

information (step ST2). The emotion module selects the emotion unit having the maximum emotion level from among the emotion units having the emotion levels exceeding the threshold value.

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The selected emotion unit notifies the object that is requesting the output, for example, the behavior-production object, of that information. --

IN THE CLAIMS

Please add the following claims.

93. (new) A robot device having a multi-joint driving unit, comprising:

means for holding a recognition object constructed by an object-oriented design, the recognition object being adapted for recognizing input information and notifying of a result of recognition;

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means for holding an emotion model object constructed by an object-oriented design, the emotion model object having the result of recognition of the recognition object inputted thereto and being adapted for changing an emotion level in accordance with the input information; and

means for holding an action generation object constructed by an object-oriented design, the action generation object being adapted for causing the robot device to act by controlling the

multi-joint driving unit on the basis of information from the emotion model object.

94. (new) A robot device having a multi-joint driving unit, comprising:

means for holding a recognition object constructed by an object-oriented design, the recognition object being adapted for recognizing an internal state and notifying of a result of recognition;

means for holding an instinct model object constructed by an object-oriented design, the instinct model object having the result of recognition of the recognition object inputted thereto and being adapted for changing an instinct level in accordance with the input information; and

means for holding an action generation object constructed by an object-oriented design, the action generation object being adapted for causing the robot device to act by controlling the multi-joint driving unit on the basis of information from the instinct model object.

95. (new) An action control method for a robot device having a multi-joint driving unit, the method comprising:

a step of notifying an emotion model object constructed by an object-oriented design, of a result of recognition from a recognition object constructed by an object oriented design and

adapted for recognizing input information;

a step of changing an emotion level in accordance with the information of the result of recognition of the recognition object inputted to the emotion model object; and

a step of causing the robot device to act by controlling the multi-joint driving unit by an action generation object constructed by an object-oriented design on the basis of information from the emotion model object.

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contd 96. (new) An action control method for a robot device having a multi-joint driving unit, the method comprising:

a step of notifying an instinct model object constructed by an object-oriented design, of a result of recognition from a recognition object constructed by an object oriented design and adapted for recognizing an internal state;

a step of changing an instinct level in accordance with the information of the result of recognition of the recognition object inputted to the instinct model object; and

a step of causing the robot device to act by controlling the multi-joint driving unit by an action generation object constructed by an object-oriented design on the basis of information from the instinct model object.

97. (new) A recording medium in which a program for controlling an action of a robot device having a multi-joint

driving unit is recorded, the program being adapted, for
executing:

a step of notifying an emotion model object constructed by
an object-oriented design, of a result of recognition from a
recognition object constructed by an object oriented design and
adapted for recognizing input information;

a step of changing an emotion level in accordance with the
information of the result of recognition of the recognition
object inputted to the emotion model object; and

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a step of causing the robot device to act by controlling the
multi-joint driving unit by an action generation object
constructed by an object-oriented design on the basis of
information from the emotion model object.

98. (new) A recording medium in which a program for
controlling an action of a robot device having a multi-joint
driving unit is recorded, the program being adapted for
executing:

a step of notifying an instinct model object constructed by
an object-oriented design, of a result of recognition from a
recognition object constructed by an object oriented design and
adapted for recognizing an internal state;

a step of changing an instinct level in accordance with the
information of the result of recognition of the recognition
object inputted to the instinct model object; and

a step of causing the robot device to act by controlling the multi-joint driving unit by an- action generation object constructed by an object-oriented design on the basis of information from the instinct model object.

99. (new) A robot device having a multi-joint driving unit, comprising:

external state detection means for detecting an external state;

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an emotion module having a value changing on the basis of the detected external state; action generation control means for controlling the multi-joint driving unit on the basis of the value of the emotion module; and

communication means for receiving a value of an emotion module of another robot device;

wherein the value of the emotion module of the robot device changes on the basis of the value of the emotion module of said another robot device received by the communication means.

100. (new) A robot device having a multi-joint driving unit, comprising:

external state detection means for detecting an external state;

an emotion module having a value changing on the basis of the detected external state;

action generation control means for controlling the multi-joint driving unit on the basis of the value of the emotion module; and

communication means for receiving a value of an emotion module of another robot device;

wherein the action generation control means generates a predetermined action on the basis of the value of the emotion module of said another robot device received by the communication means.

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contd

101. (new) An action control method for a robot device for controlling an action of a robot device having a multi-joint driving unit, the method comprising:

an external state detection step of detecting an external state;

a value change step of changing a value of an emotion module on the basis of the detected external state;

an action generation control step of controlling the multi-joint driving unit on the basis of the changed value of the emotion module; and a reception step of receiving a value of an emotion module of another robot device by communication means;

wherein the value of the emotion module of the robot device changes on the basis of the value of the emotion module of said another robot device received by the communication means.

102. (new) An action control method for a robot device for controlling an action of a robot device having a multi-joint driving unit, the method comprising:

an external state detection step of detecting an external state;

a value change step of changing a value of an emotion module on the basis of the detected external state;

an action generation control step of controlling the multi-joint driving unit on the basis of the changed value of the emotion module; and

a reception step of receiving a value of an emotion module of another robot device;

wherein at the action generation control step, a predetermined action is generated on the basis of the value of the emotion module of said another robot device received by the communication means.

103. (new) A recording medium in which a program for controlling an action of a robot device having a multi-joint driving unit is recorded, the program comprising:

an external state detection step of detecting an external state of the robot device;

a value change step of changing a value of an emotion module of the robot device on the basis of the detected external state;

an action generation control step of controlling the

multi-joint driving unit on the basis of the changed value of the emotion module; and

a reception step of receiving a value of an emotion module of another robot device by communication means;

wherein the program controls the value of the emotion module of the robot device so that the value changes on the basis of the value of the emotion module of said another robot device received by the communication means.

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104. (new) A recording medium in which a program for controlling an action of a robot device having a multi-joint driving unit is recorded, the program comprising:

an external state detection step of detecting an external state of the robot device;

a value change step of changing a value of an emotion module of the robot device on the basis of the detected external state;

an action generation control step of controlling the multi-joint driving unit on the basis of the changed value of the emotion module; and

a reception step of receiving a value of an emotion module of another robot device;

wherein the program controls so that at the action; generation control step, a predetermined action is generated on the basis of the value of the emotion module of said another robot device received by the communication means.